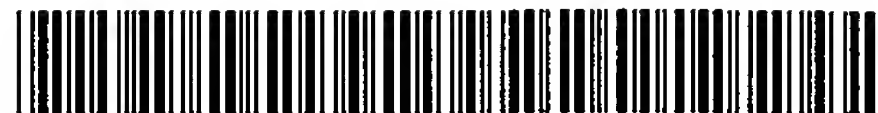


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(11) **EP 1 017 044 A1**

(12) **EUROPEAN PATENT APPLICATION**

(43) Date of publication:  
05.07.2000 Bulletin 2000/27

(51) Int. Cl.<sup>7</sup>: **G11B 7/09**

(21) Application number: 98830796.3

(22) Date of filing: 29.12.1998

(84) Designated Contracting States:  
**AT BE CH CY DE DK ES FI FR GB GR IE IT LI LU  
MC NL PT SE**  
Designated Extension States:  
**AL LT LV MK RO SI**

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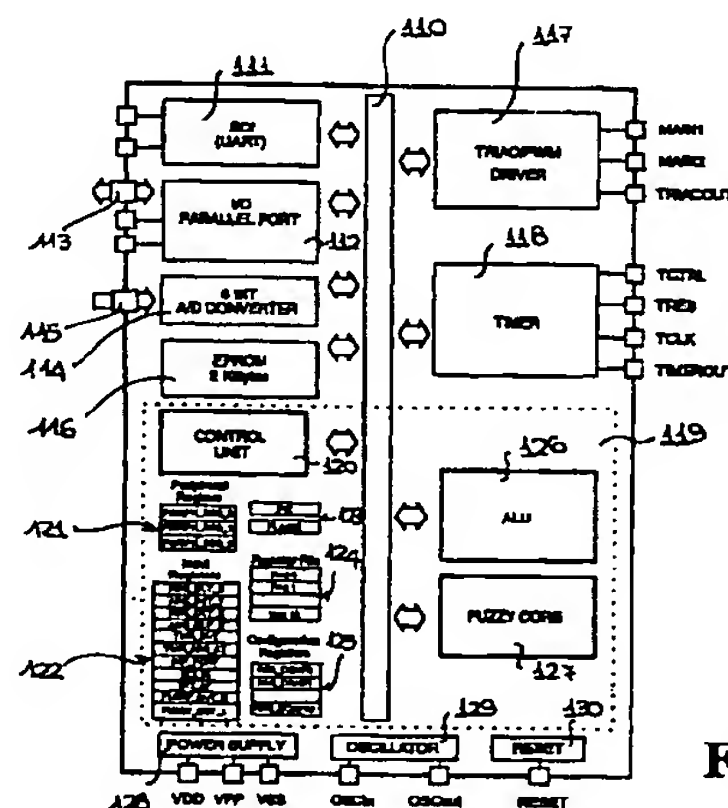
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(54) **Control device for a focus system of a CD driver using the Fuzzy logic**

(57) A control device for a focus system of a compact disk (CD) driver (1), using fuzzy logic, of the type which is incorporated to an audio data processing system (2) of the CD driver and adapted to detect and segregate a light beam reflected by the surface of the compact disk (CD) from an incident light beam to the surface.

The control device comprises, according to this invention, a controller (CF) operated on fuzzy logic for determining a focus error signal [Focus Error] and driving a focus servo-system (3) of the CD driver to adjust the distance of the focal plane from the light beam detecting means.



**FIG. 11**

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## Description

### Field of the Invention

[0001] This invention relates to a control device for a focus system of a CD driver using fuzzy logic.

[0002] The invention specifically relates to a control device for a focus system of a CD (Compact Disk) reader, using fuzzy logic, the device being incorporated to an audio data processing system of the CD driver adapted to detect and segregate a light beam reflected by the surface of the compact disk from an incident light beam to the surface.

[0003] The invention, particularly but not exclusively, relates to a focus control device for a source of monochromatic light in an audio data processing system of a CD driver, and the description which follows will cover that field of application for convenience of explanation.

### Prior Art

[0004] As is well known, each CD driver contains two primary systems: an audio data processing system and a control servo-system.

[0005] A CD driver is shown schematically at 1 in Figure 1. The CD driver 1 has a data input terminal IN, a servo-control output terminal O1, and first O2 and second O3 data output terminals.

[0006] An audio data processing system 2 is connected between the data input terminal IN and the data output terminals O2 and O3, and comprises a series of a buffer 4, an error corrector 5, an interpolation-muting (or concealment) and demultiplexing block 6, a digital filter 7, D/A converters 8 and 8', and analog output filters 9 and 9'.

[0007] The audio data processing system 2 also includes a storage device 10, such as a RAM, which is connected bi-directionally to said error corrector 6 and adapted to store the data during the audio data de-interleaving phase.

[0008] The input terminal IN of the CD driver 1 is connected to a series of a bit detection device 11, itself connected to the servo-control output terminal O1 via a control servo-system 3, and a demodulator 12. The CD driver 1 further includes a control/display subsystem 13 connected to said demodulator 12 and to the buffer 4 of the audio data processing system 2, which subsystem comprises a series of a decoding block 14, a function controlling device 15, and a display 16.

[0009] The control servo-system 3 and the control/display subsystem 13 are to control the mechanical operations of the CD driver 1, including auto-tracking, auto-focus, and user's interface functions.

[0010] The data reading system 2 uses a semiconductor laser, the light beam whereof must be kept on focus for tracking Pit. A motor is used for turning the disk at a constant linear velocity, as well as to change its

speed according to the position of the pickup on the surface of the compact disk. The information supplied in the data is used for establishing the appropriate rotational rate and keeping the output data stream constant.

[0011] Finally, the CD driver 1 includes a clock signal generator block 17, having its input connected to the output of the bit detection device 11 and including a clock signal regenerator 18 connected to an elementary clock signal generator 19 which may be provided with a piezo-electric crystal 20.

[0012] As said before, the optical system of the CD driver 1 employs a monochromatic light source, specifically an output laser 21, which requires to be stabilized since it is a basically regenerative device whose temperature is tied to the level of the output.

[0013] Thus, in order to extract an audio data signal, the audio data processing system 2 should be capable of segregating the reflected light beam from the incident light beam. This separation can be obtained essentially in either of two manners, schematically illustrated by Figures 2A and 2B. In Figure 2A, a half-mirror 22 directs the light beam reflected from a disk 23 onto a light sensor 24.

[0014] This known system is not very efficient because some of the light is lost along the direct transmission path.

[0015] Figure 2B illustrates the combined use of a polarizing prism 25 and a quarter-wave plate for segregating the incident light beam from the reflected beam, which combination improves the system performance.

[0016] Both systems shown in Figures 2A and 2B employ a focus laser lens LF as a means to focus the light beam.

[0017] It should be borne in mind that the frequency response of a CD audio channel and the amount of crosstalk are functions of the spot size, that is to say, they are basic variables tied to the device optics.

[0018] The performance of a CD driver 1 is dependent on the detection and focusing of the light beam on the informational layer of a compact disk.

[0019] Devices effective to keep under control the system response to disturbance of large amplitude, by means of an algorithm based on binary logic, have been known, but such devices are complicated and low in efficiency.

[0020] The underlying technical problem of this invention is to provide a focus system controller for a CD driver, which can solve the problem of controlling the system response to disturbance of large amplitude in a simple and efficient manner, and thus overcome the drawbacks which beset the prior art devices.

### Summary of the Invention

[0021] The principle of this invention is one of providing a focus system controller which is very simple, yet efficient, using fuzzy logic.

[0022] Based on this idea of solution, the technical

problem is solved by a focus system controller as previously indicated and defined in the characterizing portion of Claim 1.

[0023] The features and advantages of a controller according to the invention will be apparent from the following description of an embodiment thereof, given by way of non-limitative example with reference to the accompanying drawings.

#### Brief Description of the Drawings

[0024] In the drawings:

Figure 1 shows schematically the structure of a conventional CD driver, incorporating an audio data processing system and a control servo-system;

Figures 2A and 2B illustrate first and second schemes for segregating a reflected light beam from an incident light beam;

Figure 3 shows a photodiode type of optical mechanism;

Figure 4 is a theoretical plot of a focus error signal;

Figure 5 shows a simulation scheme for the PD (Proportional-Derivative) controller;

Figures 6A and 6B show the results of the simulation of Figure 5;

Figure 7 shows a simulation scheme for obtaining a fuzzy controller starting from the PD controller of Figure 5;

Figures 8A, 8B and 9 show membership functions found from the scheme of Figure 7;

Figure 10A shows a further simulation scheme for the fuzzy controller according to the invention;

Figure 10B shows the result of the simulation of Figure 10A;

Figure 11 shows schematically the structure of a fuzzy controller according to the invention;

Figures 12A and 12B show the membership functions of a parallel fuzzy controller;

Figure 13 shows a simulation scheme for the parallel fuzzy controller;

Figure 14 shows the result of the simulation of Figure 13;

Figure 15 shows the result of comparing the per-

formance of a conventional controller with that of a fuzzy controller according to the invention;

Figure 16 illustrates a fuzzy development system of the fuzzy controller according to the invention;

Figures 17A and 17B show the results of a simulation at the oscilloscope of signals obtained with the fuzzy controller of this invention; and

Figure 18 shows the result of a simulation carried out on a modified embodiment of the fuzzy controller according to the invention.

#### Detailed Description

[0025] As mentioned above, the performance of a CD driver 1 is affected by the detection and focusing of the light beam on the informational layer of an optical disk or CD.

[0026] Bends in the CD and the depth of its surface unevenness cause the focal plane to shift, so that a focus servo-system must be used. The accuracy of this servo-system should be adequate to keep the focal plane at optimum range within an error of  $\pm 1\mu\text{m}$ .

[0027] Simulations have been carried out by the Applicant on a CD-ROM 8x driver whose characteristics are as specified by the Red Book standard. This driver affords fast radial access and can operate within a wide range of temperatures.

[0028] Advantageously in this invention, a so-called Single Foucault method is used for determining a focus error signal [Focus Error], i.e. a signal which enables the position of the focal point to be found. A photodiode type of optical mechanism 27, comprising five photodiodes, is shown schematically in Figure 3. The photodiode optical mechanism 27 has two outboard diodes (D1, D5), referred to as the satellite diodes, which are used solely for tracking purposes, and three middle diodes (D2, D3, D4) which are used for determining the focus error signal [Focus Error Detection].

[0029] Figure 4 is a theoretical plot of the focus error signal [Focus Error] as suitably normalized according to the following expression:

$$FEn = 2 * \text{Error}$$

[0030] As is apparent from Figure 4, the focus error signal [Focus Error] is a function of the displacement of the light beam focus means, specifically the focus laser lens LF shown in Figures 2A and 2B which illustrate the state of the art.

[0031] On the graph of Figure 4, the origin point of the axis z corresponds to the lens setting when the laser is properly focused.

[0032] From the pattern of the focus error signal FE, a controller CF of the audio data processing system 2 can be determined which is operative to keep the laser

light source focused onto the compact disk surface.

[0033] The design specifications for this controller CF come into two major classes:

- those covering the behavior of the controlled system in the steady-state or asymptotic condition; and
- those covering the behaviour of the controlled system in the transient range, in response to canonical input signals.

[0034] In the instance considered, the controlled system is asymptotically stable. It should be further noted that the steady-state error is not required to be zero, because it will be sufficient for the system to have the laser lens set such that the light beam is focused within an error of  $1\mu\text{m}$ .

[0035] As for the behavior in the transient range, it is important to obtain a sufficiently large phase margin for the frequency response of the controlled system.

[0036] In particular, an acceptable minimum value for that margin may be  $60^\circ$ . In this way, the optical system can produce a prompt response, that is, will react quickly to stimuli.

[0037] In order for the system to be the quicker to respond, a rise time of less than .01 seconds in the frequency response is to be preferred.

[0038] Thus, the specifications for the photodiode optical system 27 can be itemized as follows:

- a steady-state error which need not be zero;
- a phase margin  $m_\phi = 60^\circ$ ;
- a rise time  $t_s \leq 0.01$  sec.

[0039] At this point, the above specifications should be converted into useful parameters to synthesize the focus system controller CF; in particular, once the phase margin and rise time have been decided upon, the corresponding values of the dampening factor and the cut-off frequency can be determined. The last-mentioned parameter can be useful to a synthesis method based on frequency response.

[0040] Since,

$$m_\phi = \frac{\pi}{2} - \arctg \frac{\sqrt{1+4\xi^4} - 2\xi^2}{2\xi} \quad (1)$$

then,

$$\xi = 0.61 \quad (2)$$

and since,

$$t_s = \frac{1}{\omega_n} \frac{1}{\sqrt{1-\xi^2}} \left[ \pi - \arctg \frac{\sqrt{1-\xi^2}}{\xi} \right] \quad (3)$$

then,

$$\omega_n = 295 \quad (4)$$

$$\omega_n = 293$$

[0041] Therefore, a focus system controller CF capable of implementing the above method should have the following transfer function:

$$R(s) = 1.5 \frac{(1+0.0044s)}{(1+0.000317s)} \quad (5)$$

[0042] It can be at once appreciated that the  $s$  term in the denominator is so much smaller than 1 that it can be safely ignored, and the transfer function of a conventional PD (Proportional-Derivative) controller becomes:

$$R(s) = 1.5 (1 + 0.0044s) \quad (6)$$

[0043] A final consideration to be made about the controller just found concerns the controller capability to keep the system focused while the plant, i.e. the mechanical system and the lens, is subjected to vibration, which represents a major source of disturbance to a CD driver. For the purpose, the behavior of the control system in reverse feedback was simulated, with the addition of a noise input to the plant to simulate real vibration. The scheme adopted for this simulation is illustrated by Figure 5, and the result of the simulation is reported in Figures 6A and 6B.

[0044] In particular, Figure 5 shows schematically a controller 50 having the transfer function  $R(s)$  given by expression (6) above.

[0045] The controller 50 has its output connected to a summing node 51 which receives in parallel a signal representing the noise, schematically illustrated by a noise block 52 outputting a vibration signal  $S1$ . The summing node 52 is cascade connected to a plant block 53 which has an output fed back to the controller 50 input and arranged to supply a focus error signal  $S2$ .

[0046] The signal shown in Figure 6A represents the noise  $S1$  at the system input. Figure 6B shows that the focus error signal  $S2$  is virtually zero even as the system is subjected to vibration.

[0047] Advantageously in this invention, based on the parameters yielded by this simulation, a fuzzy controller for the focus control system of the CD driver is provided by "fuzzifying" a standard controller  $R(s)$ .

[0048] For the purpose, a special neuro-fuzzy system, and an associated algorithm developed by the Applicant and designated AFM, have been used which allow a fuzzy model of a system to be generated from a



measurement of its input/output data.

[0049] The first step of this process is the taking of measurements on the system to be modelled. To this aim, the Simulink toolbox of Matlab has been utilized which, based on the scheme shown in Figure 7, allows the input data (error and error derivative) to the fuzzy controller and its output to be measured.

[0050] The scheme in Figure 7 comprises a controller 70 having its output connected to a summing node 71 which receives in parallel a signal representing the noise, schematically illustrated by a noise block 72 outputting a vibration signal S3. The summing node 71 is cascade connected to a plant block 73 which has an output fed back to the controller 70 input and arranged to supply a focus error signal S4.

[0051] The plant block 73 is also connected with its output to a derivative block 74 adapted to supply a signal S5 being a derived function of the error S4.

[0052] Also, a control output signal S6 is picked up from the controller 70 output.

[0053] Using the AFM software, the fuzzy controller membership functions and rules have been obtained for the CD driver focus system in accordance with the invention. Shown in Figures 8A and 8B are the membership functions Mbfs relating to the focus error signal [error] and its derivative signal [derror], respectively. Figure 9 shows the membership function relating to the control output signal [du].

[0054] The fuzzy controller of this invention is defined by the following fuzzy inference rules:

IF error IS Neg AND derror IS Neg THEN du IS a  
IF error IS Neg AND derror IS Null THEN du IS b  
IF error IS Neg AND derror IS Pos THEN du IS c  
IF error IS Null AND derror IS Neg THEN du IS d  
IF error IS Null AND derror IS Null THEN du IS e  
IF error IS Null AND derror IS Pos THEN du IS f  
IF error IS Pos AND derror IS Neg THEN du IS g  
IF error IS Pos AND derror IS Null THEN du IS h  
IF error IS Pos AND derror IS Pos THEN du IS i

where:

Neg, Null and Pos denote negative, zero, and positive values, respectively, for the membership functions (MF in Figures 8A and 8B); and

a, b, c, d, e, f, g, h and i denote the results to be applied to the control output signal shown in Figure 9.

[0055] To carry out simulations by Matlab of the fuzzy controller thus defined, a Matlab file has been created according to the scheme shown in Figure 10A. The result of the simulation is shown in Figure 10B.

[0056] The scheme shown in Figure 10A provides for a summing node 101 to receive in parallel a signal representing the noise, schematically illustrated by a

noise block 102 outputting a vibration signal S7. The summing node 101 is cascade connected to a plant block 103 having an output for supplying a focus error signal S8.

[0057] The plant block 103 is also connected with its output to a derivative block 104, itself connected to a multiplexer 105 which is input the focus error signal S8 as well.

[0058] The multiplexer 105 is further connected to a Matlab simulation block 106 representing the functions of the fuzzy controller according to the invention and being in turn connected to the summing node 101.

[0059] The fuzzy controller thus obtained is shown schematically in Figure 11 and generally referenced CF.

[0060] In particular, the controller CF is constructed around a central communications bus 110 which is connected bi-directionally to:

- a transmitter-receiver block 111 connected with its input to a transmit terminal Tx and a receive terminal Rx;
- a parallel input/output (I/O) gate 112 connected with its input to first PV and second READV terminals, and connected bi-directionally to a data bus 113;
- an 8-bit analog-to-digital (A/D) converter connected with its input unidirectionally to another data bus 115; and
- a storage device 116, specifically a 2-kbyte EPROM.

[0061] The central communications bus 110 is also connected bi-directionally to:

- a drive block 117 connected to first MAIN1 and second MAIN2 supply terminals, as well as connected to a drive terminal TRIACOUT; and
- a timer 118 connected to first TCTRL, second TRES, third TCLK and fourth TIMEROOUT timing terminals.

[0062] The fuzzy controller CF includes a calculation subsystem 119 which is connected bi-directionally to the central communications bus 110 and comprises:

- a control unit 120 acting on a first set of peripheral registers 121, a second set of input registers 122, a third set of signalling registers 123, a fourth set of storage registers 124, and a fifth set of formatting registers 125;
- a central calculation unit [ALU] 126; and
- a fuzzy device 127.

[0063] The fuzzy controller CF further includes: a power generator 128 connected to first VDD, second VPP and third VSS supply terminals; an oscillator 129 connected to an input terminal OSCin and an output terminal OSCout; and a reset circuit 130 connected to a reset terminal RESET.

[0064] An important problem with conventional CD driver focus systems is a loss of the focal point position in the presence of very strong disturbance.

[0065] In fact, conventional controllers are unable to prevent such loss of the system focus.

[0066] Advantageously in this invention, this problem is obviated through the use of fuzzy logic. Thus, a parallel controller is provided by means of a fuzzy algorithm that, as explained hereinafter, is quite simple, yet efficient.

[0067] The fuzzy model of the parallel controller is to generate, upon the main fuzzy system losing control, a ramp tending to restore the system to its previous condition.

[0068] For the purpose, an algorithm has been devised which can determine whether the lens has been moved away from or close to the disk, and accordingly increase or decrease a variable for generating a ramp with the appropriate sign. During the time when this parallel controller is not required to operate, the fuzzy algorithm holds its output at zero level.

[0069] This algorithm is implemented with a single input variable, the error signal, three membership functions [Membership Function], and an output variable having one of three possible values:

-1 to increase the variable;

0 when not required to act;

+1 to decrease the variable.

[0070] Shown in Figures 12A and 12B are the fuzzy sets of the variables corresponding to the error signals and the output signal, respectively. The rules of the fuzzy algorithm for the parallel controller of this invention are the following:

IF error IS Neg THEN out IS ml  
IF error IS Pos THEN out IS pl  
IF error IS Zero THEN out IS xl

where:

error is the membership function relating to the error signal input to the parallel controller;

out is the membership function relating to the output signal from the parallel controller;

Neg, Zero and Pos denote negative, zero and positive values, respectively, for the functions consid-

ered; and

ml, pl and xl denote the results to be applied to the parallel controller output signal.

[0071] The Simulink scheme used is illustrated by Figure 13. It provides a summing node 131 which receives in parallel a signal representing the noise, schematically illustrated by a noise block 132. The summing node 131 is cascade connected to a plant block 133 which has an output arranged to supply a focus error signal S9.

[0072] The summing node 131 input is connected to a switch 134.

[0073] The scheme of Figure 13 further provides a Matlab simulation block 135, representing the functions of the ramp-generating parallel controller, itself connected via a selection block 136 (shown in phantom lines to indicate discontinuity of connection) to the switch 134, and connected to a further summing node 137, itself connected with its input to a series of a derivative block 138, a multiplexer 139 and a second Matlab simulation block 140 representing the function of the inventive controller, in turn connected to the summing node 137.

[0074] Finally, the input of the switch 134 is connected to yet another summing node 141, itself connected with its input to first 142 and second 143 relay blocks.

[0075] The two relay blocks 142 and 143 are used to determine, in simulated form, the signal that in actual practice would be supplied by the system hardware.

[0076] Finally, the output from the plant block 133 is fed back to the derivative block 138, and fed forward to the multiplexer 139, the relay blocks 142 and 143, and the first Matlab simulation block 135.

[0077] Figure 14 shows the result of the simulation.

[0078] Thus, the resultant fuzzy controller can solve the problem of the system responding to disturbance of large amplitude, in a simpler and more efficient manner than by utilizing an algorithm based on binary logic.

[0079] To confirm the improved performance brought about by the fuzzy controller of the invention, this has been tested in comparison with a conventional PD controller.

[0080] The comparative test concerned the response of the system controlled by the fuzzy controller (not the parallel controller) to an input having an amplitude step of .05. The test result is as shown in Figure 15.

[0081] Although the PD controller gives a faster response, the fuzzy controller of this invention has proved more efficient in determining the focal point position. In fact, the final position error is approximately .005, corresponding to a 3.25 $\mu$ m deviation from true focus position, for the PD controller, and approximately .001, corresponding to a 0.65 $\mu$ m deviation from true focus position, for the fuzzy controller.

[0082] It should be noted that a zero error is not needed, i.e. the lens is not required to be set exactly, and that it is enough for the error to be held within  $\pm 1 \mu\text{m}$  of the true position. It seems safe to conclude, therefore, that unlike the PD controller, the fuzzy controller fills this demand by a good margin.

[0083] For testing on the real system, a previously designed fuzzy adjuster has been implemented on a microprocessor sold by the Applicant as brand ST52, using the Fuzzystudio 3.0 development system.

[0084] The fuzzy development scheme thus obtained for the controller of this invention is illustrated by Figure 16. This scheme provides in particular a fuzzy block, Fuzzy0, whereinto the rules and fuzzy sets of the algorithm to be implemented are placed.

[0085] To best demonstrate the results of a fuzzy controller thus formed, three signals have been displayed on the oscilloscope, namely: a focus error signal [Focus Error], a focus signal [Casum (Central Aperture SUM)], and a digital information signal [Hf], as plotted in Figures 17A and 17B.

[0086] The proper operation of the controller is confirmed by the focus error signal [Focus Error] being held around a zero value and the focus signal [Casum] held at a high level.

[0087] As a further confirmation, the digital information signal Hf, from which signal the digital information is extrapolated, shows to be other than zero, and more precisely a varying signal. It should indeed be considered how a major feature of the signal Hf is that, when the system is out of focus, it would be at a zero level, whereas with the system focused -- as it happens to be in this case -- it would be other than zero or otherwise vary.

[0088] Advantageously in this invention, the fuzzy controller can be optimized by means of genetic algorithms.

[0089] In particular, the fuzzy controller described hereinabove has been optimized by varying its parameters within  $\pm 10\%$  of the interpolated value, and using for disturbance a pulse having the following characteristics: step time = 0.001; initial value = 0.3; final value = 0. The results of the simulation are reported in Figure 18.

[0090] It can be seen that the error value changes from  $1.823\text{e-}5$  (heavy line) for the standard fuzzy controller, to  $6.204\text{e-}6$  for the optimized version. Additional simulations have been carried out at different disturbance inputs, which all gave satisfactory results.

[0091] As described in the foregoing, the use of fuzzy logic effectively overcomes the problem of the focus control system response to disturbance of large amplitude, in a simpler and more efficient way than by using an algorithm based on binary logic.

[0092] Also noteworthy is that the fuzzy control described above in connection with the focus system would be equally applicable to other systems, e.g. to auto-tracking.

[0093] Further applications can be envisaged for a

fuzzy controller according to the invention in the fields of DVD systems and HD (Hard Disk) control.

## Claims

1. A control device for a focus system of a compact disk (CD) driver (1), using fuzzy logic, the device being incorporated to an audio data processing system (2) of the compact disk driver adapted to detect and segregate a light beam reflected by the surface of the compact disk (CD) from an incident light beam to the surface, characterized in that it comprises a controller (CF) operated on fuzzy logic for determining a focus error signal (Focus Error) and driving a focus servo-system (3) of the compact disk driver to adjust the distance of the focal plane from the light beam detecting means.
2. A focus system control device according to Claim 1, characterized in that it includes a photodiode optical mechanism (27) comprising two outboard photodiodes (D1,D5) used solely for tracking a track signal of the compact disk driver, and three middle diodes (D2,D3,D4) used for determining the focus error signal (Focus Error Detection).
3. A focus system control device according to Claim 1, characterized in that said controller (CF) has the following transfer function:

$$R(s) = 1.5 \frac{(1+0.0044s)}{(1+0.000317s)}$$

4. A focus system control device according to Claim 3, characterized in that said controller (CF) is defined by means of the following fuzzy inference rules:

IF error IS Neg AND derror IS Neg THEN du IS a  
 IF error IS Neg AND derror IS Null THEN du IS b  
 IF error IS Neg AND derror IS Pos THEN du IS c  
 IF error IS Null AND derror IS Neg THEN du IS d  
 IF error IS Null AND derror IS Null THEN du IS e  
 IF error IS Null AND derror IS Pos THEN du IS f  
 IF error IS Pos AND derror IS Neg THEN du IS g  
 IF error IS Pos AND derror IS Null THEN du IS h  
 IF error IS Pos AND derror IS Pos THEN du IS i

where:

error is a first fuzzy input variable correspond-

ing to the focus error signal (Focus Error);

dererror is a second fuzzy input variable corresponding to the derivative of the focus error signal (Focus Error);

5

du is a fuzzy output variable corresponding to an output signal of the controller (CF);

Neg, Null and Pos denote negative, zero, and positive values, respectively, for the fuzzy input variables; and

10

a, b, c, d, e, f, g, h and i denote the results to be applied to the fuzzy output variable.

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5. A focus system control device according to Claim 1, characterized in that it further comprises a parallel controller adapted to generate, upon the main controller (CF) losing control, a ramp tending to restore the audio data processing system (2) to a lockup condition.

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6. A focus system control device according to Claim 5, characterized in that said parallel controller comprises an algorithm for finding out whether the light beam detecting means has been moved away from or close to the compact disk (CD), and accordingly increasing or decreasing a variable to generate said ramp with the appropriate sign.

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7. A focus system control device according to Claim 6, characterized in that said algorithm of the parallel controller holds a zero output value when the main controller (CF) is in a lockup condition.

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8. A focus system control device according to Claim 7, characterized in that said algorithm of the parallel controller contains an input variable corresponding to an error signal and defined by a plurality of membership functions, and an output variable which can take any of the following three values:

40

-1 to generate a positive ramp;

45

0 when said controller is not required to act;

+1 to generate a negative ramp.

9. A focus system control device according to Claim 8, characterized in that said parallel controller is defined by means of the following fuzzy rules:

50

IF error IS Neg THEN out IS ml

IF error IS Pos THEN out IS pl

55

IF error IS Zero THEN out IS xl

where:

error is the membership function relating to the error signal input to the parallel controller;

out is the membership function relating to the output signal from the parallel controller;

Neg, Zero and Pos denote negative, zero and positive values, respectively, for the functions considered; and

ml, pl and xl denote the results to be applied to the parallel controller output signal.

10. A compact disk driver of the type incorporating an audio data processing system (2) provided with a focus system control device according to any of Claims 1 to 9.



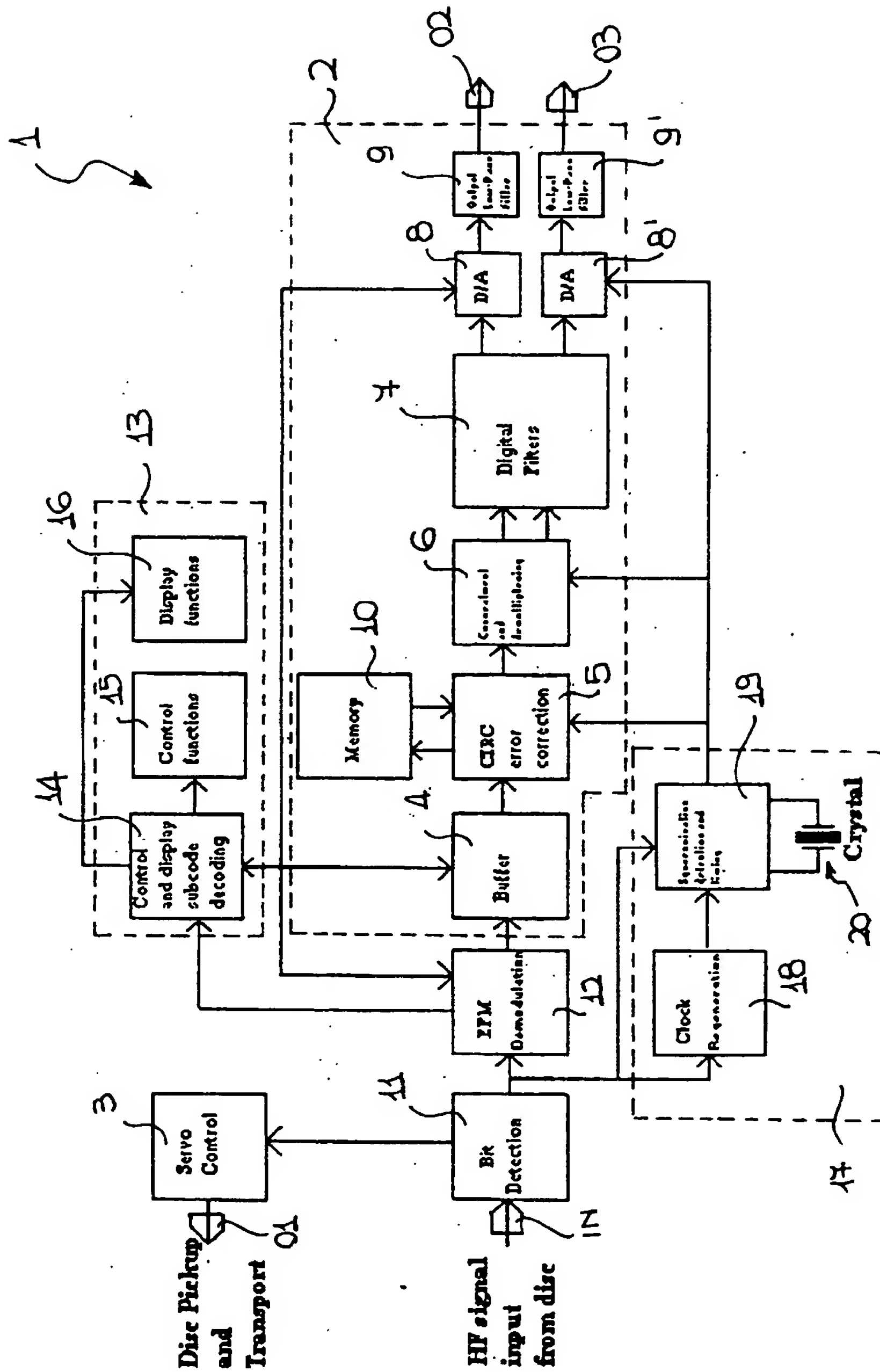
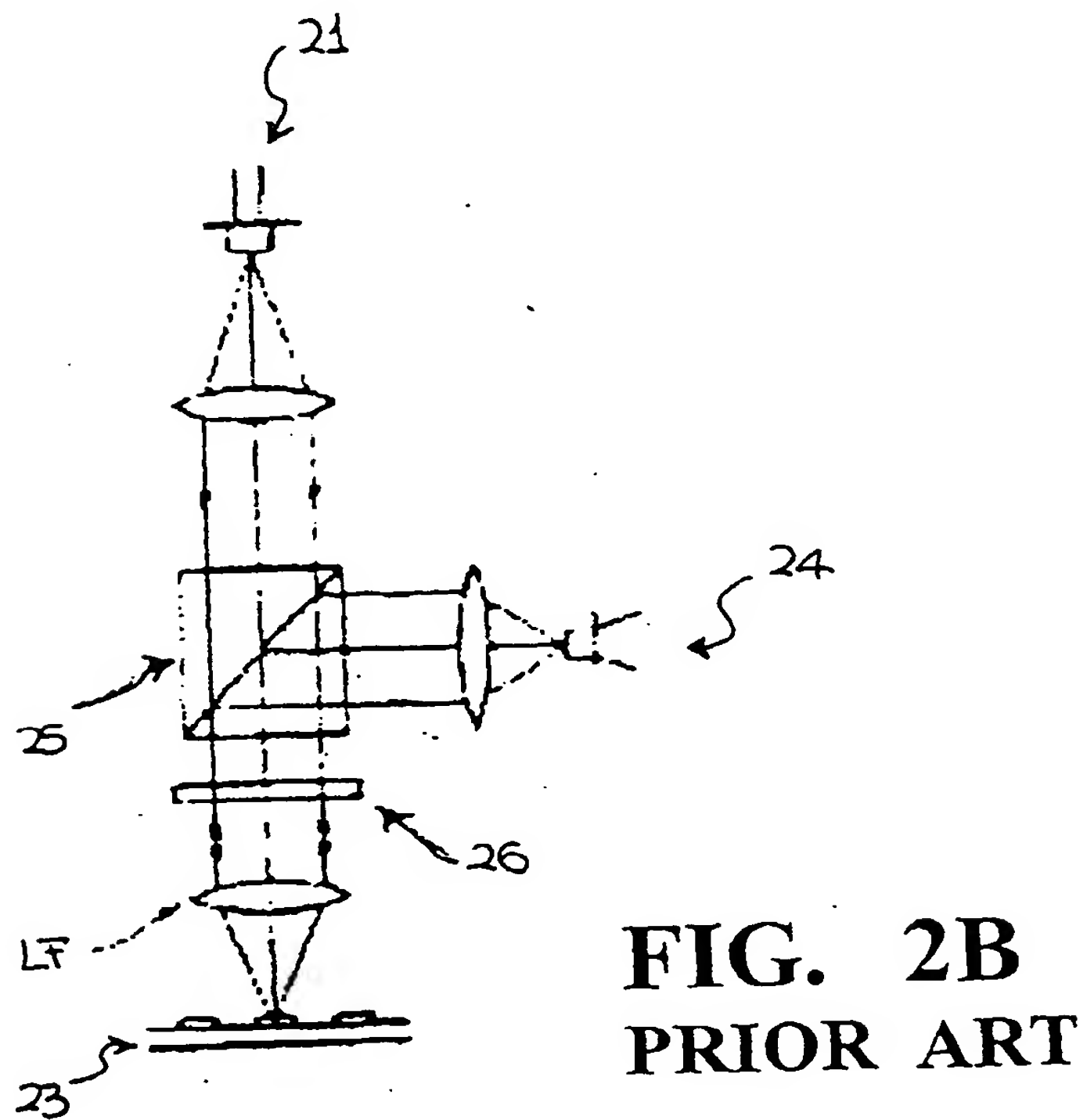
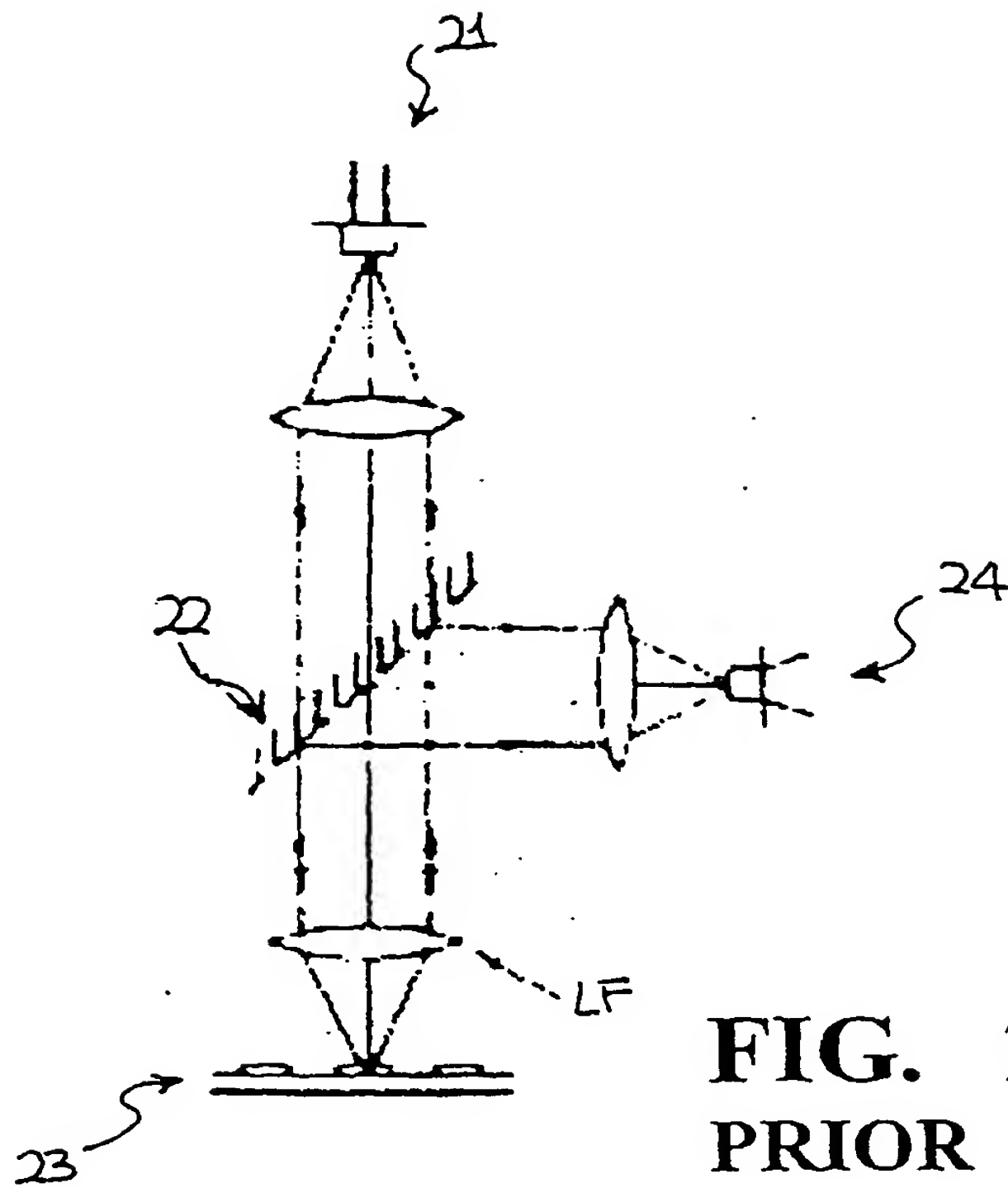


FIG. 1  
PRIOR ART



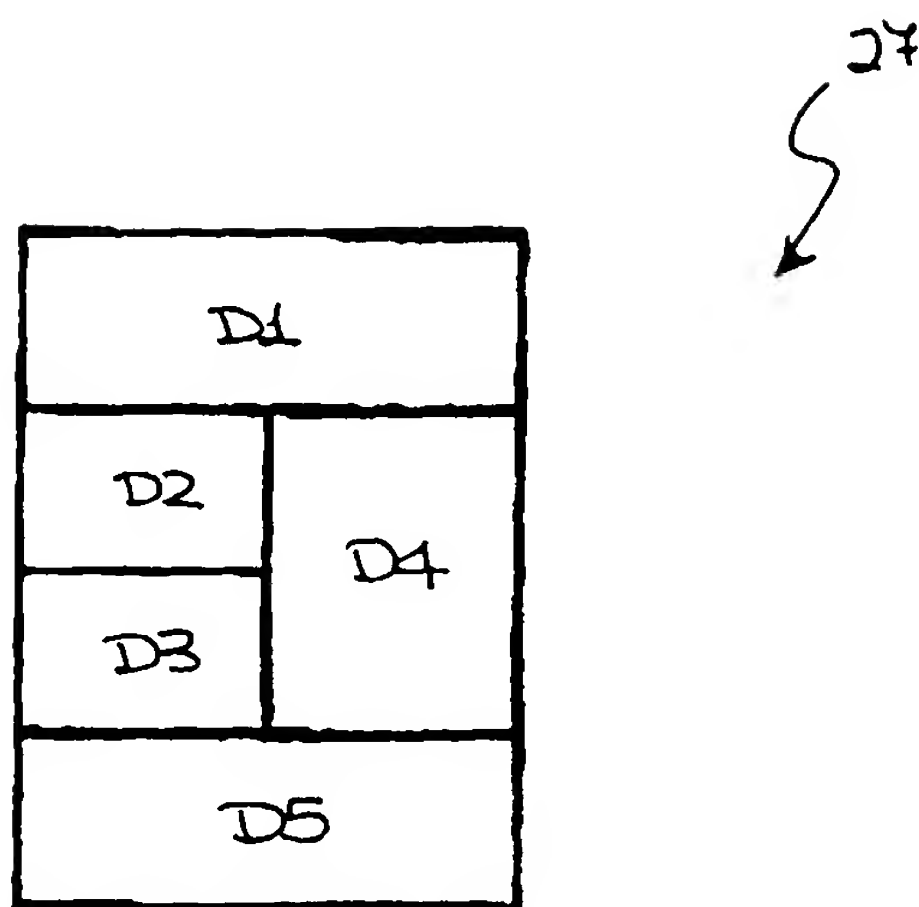


FIG. 3

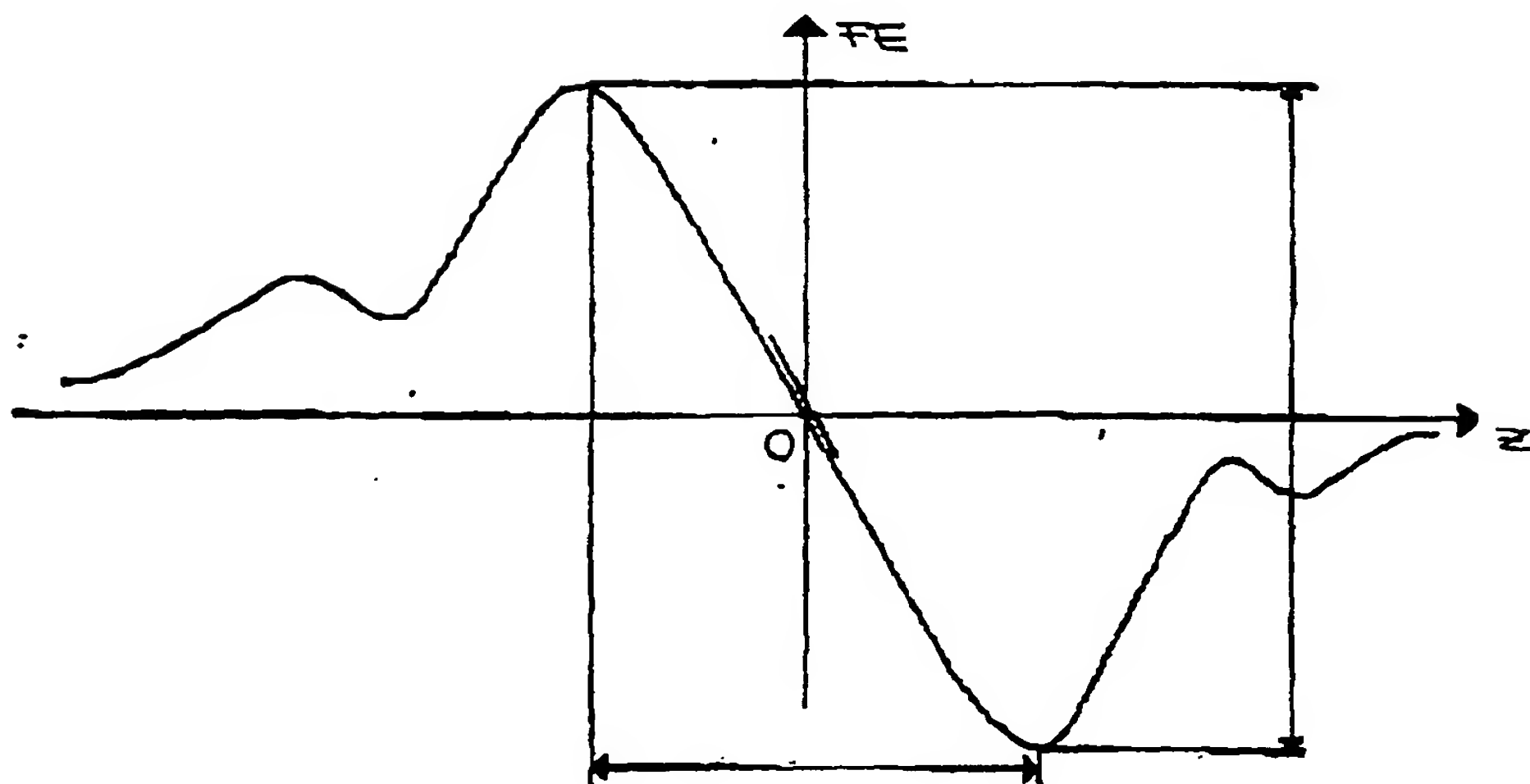


FIG. 4

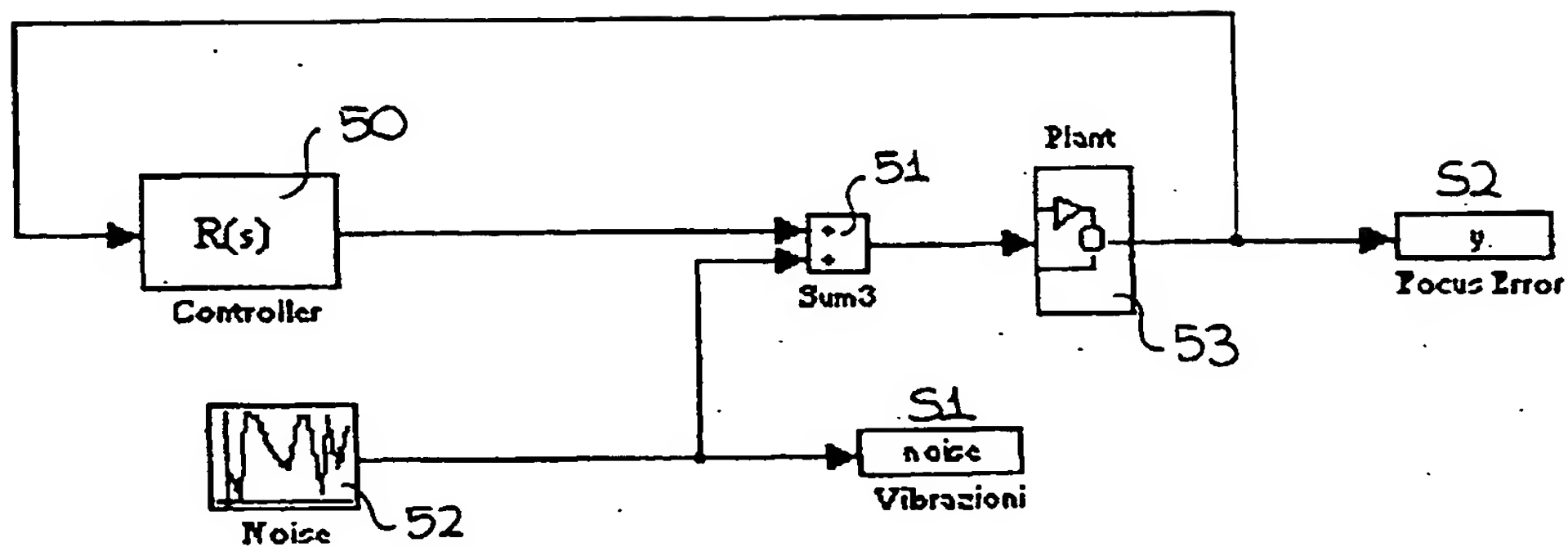


FIG. 5

FIG. 6A

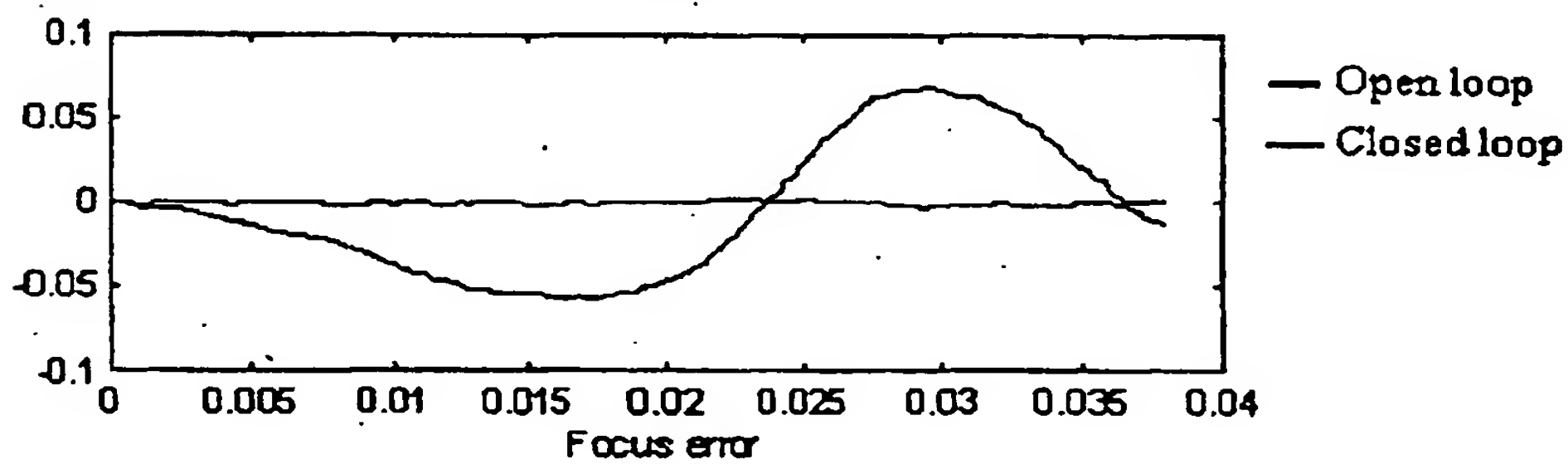
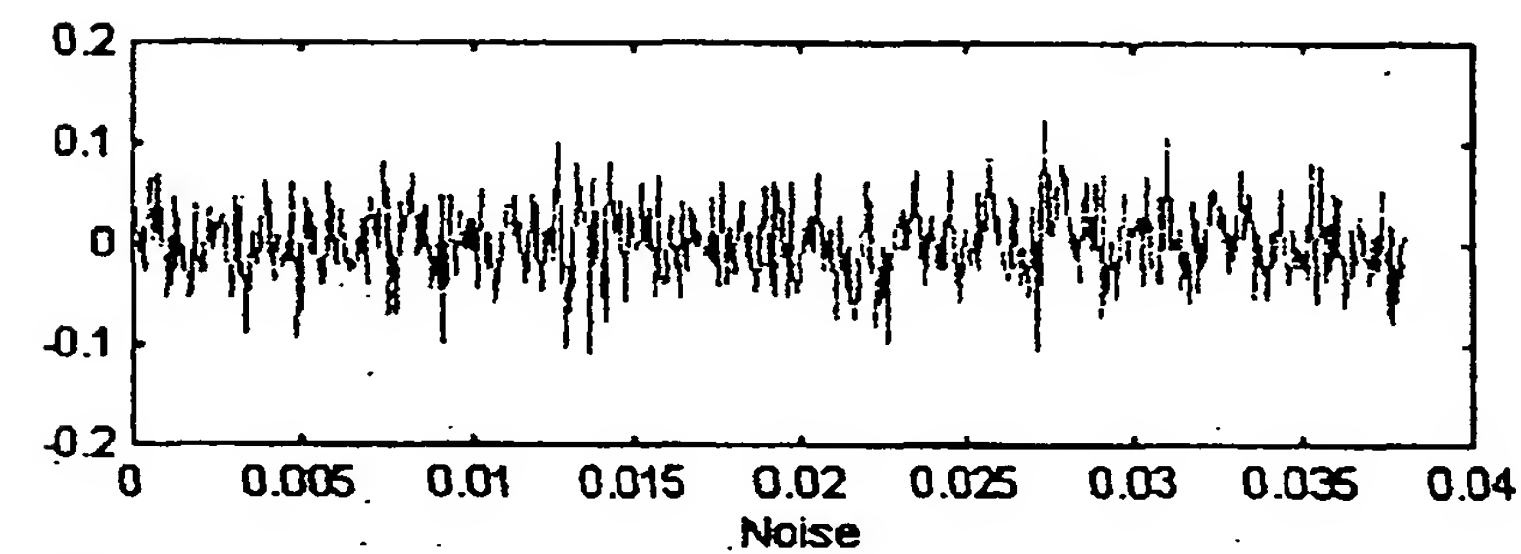


FIG. 6B



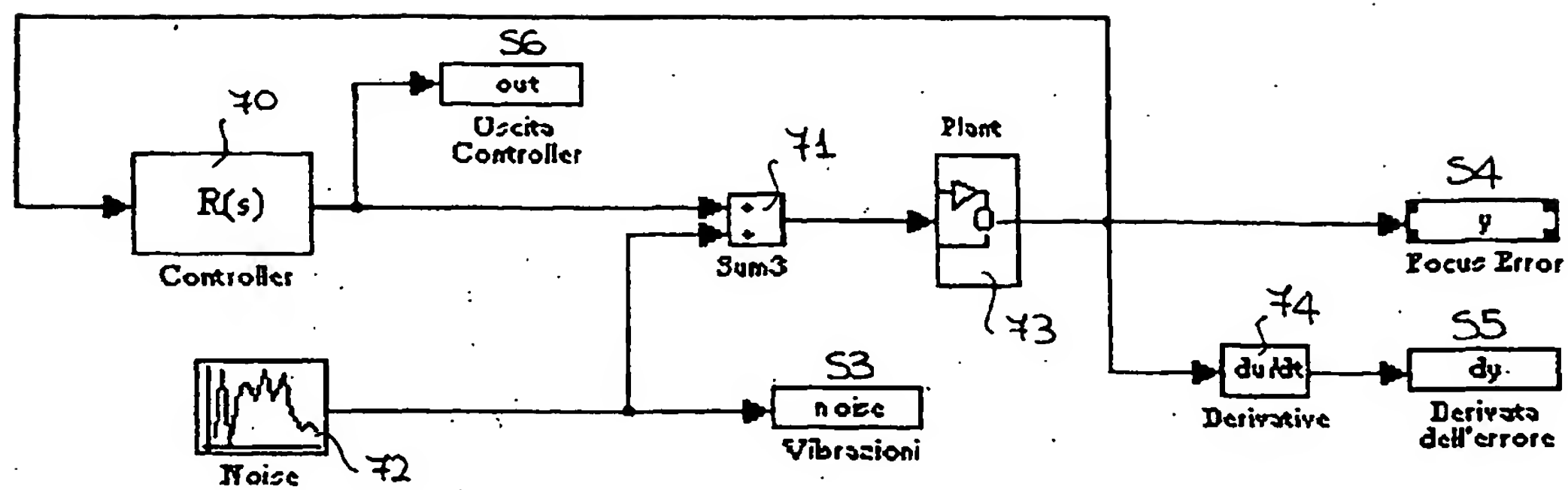


FIG. 7

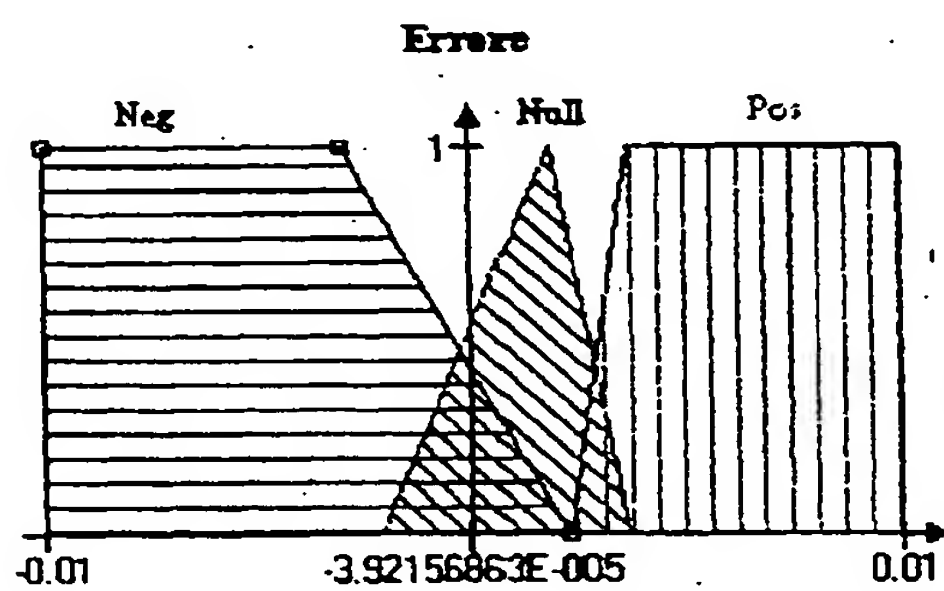


FIG. 8A

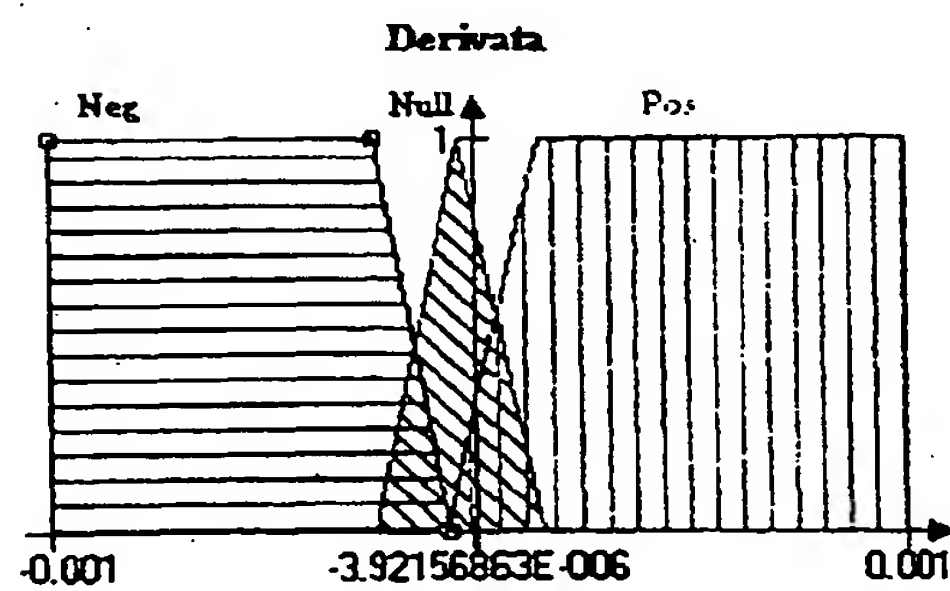


FIG. 8B

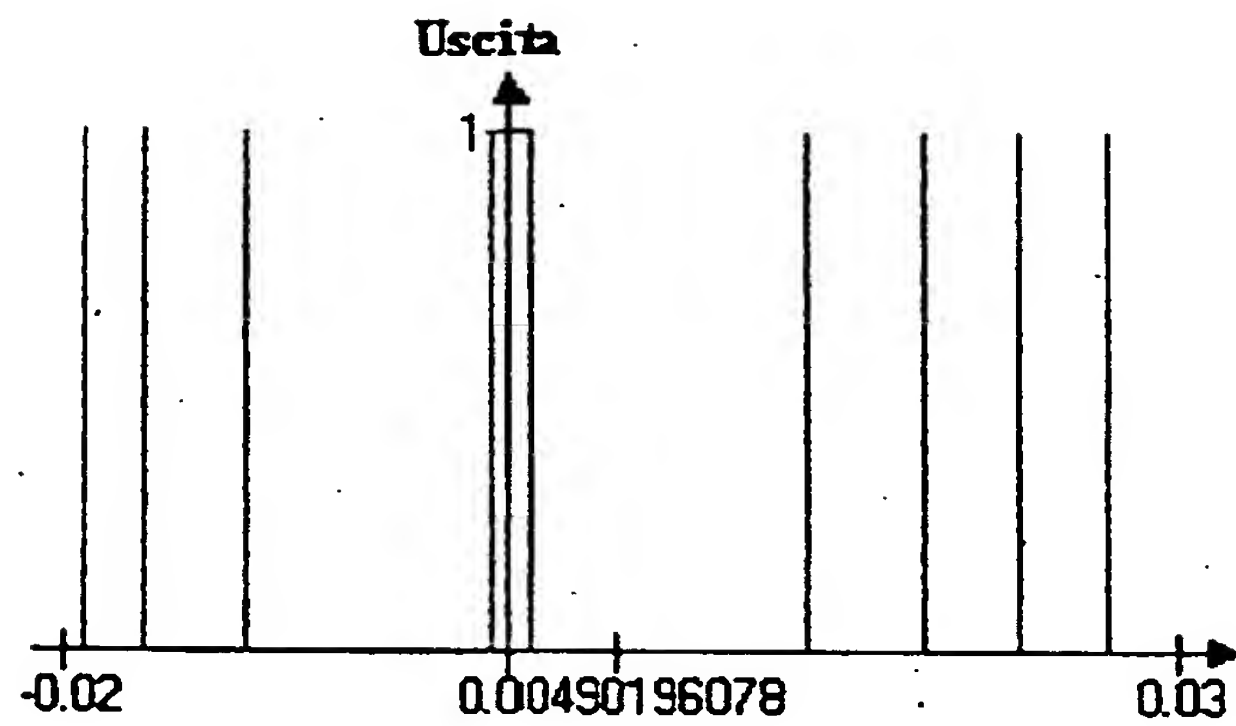


FIG. 9

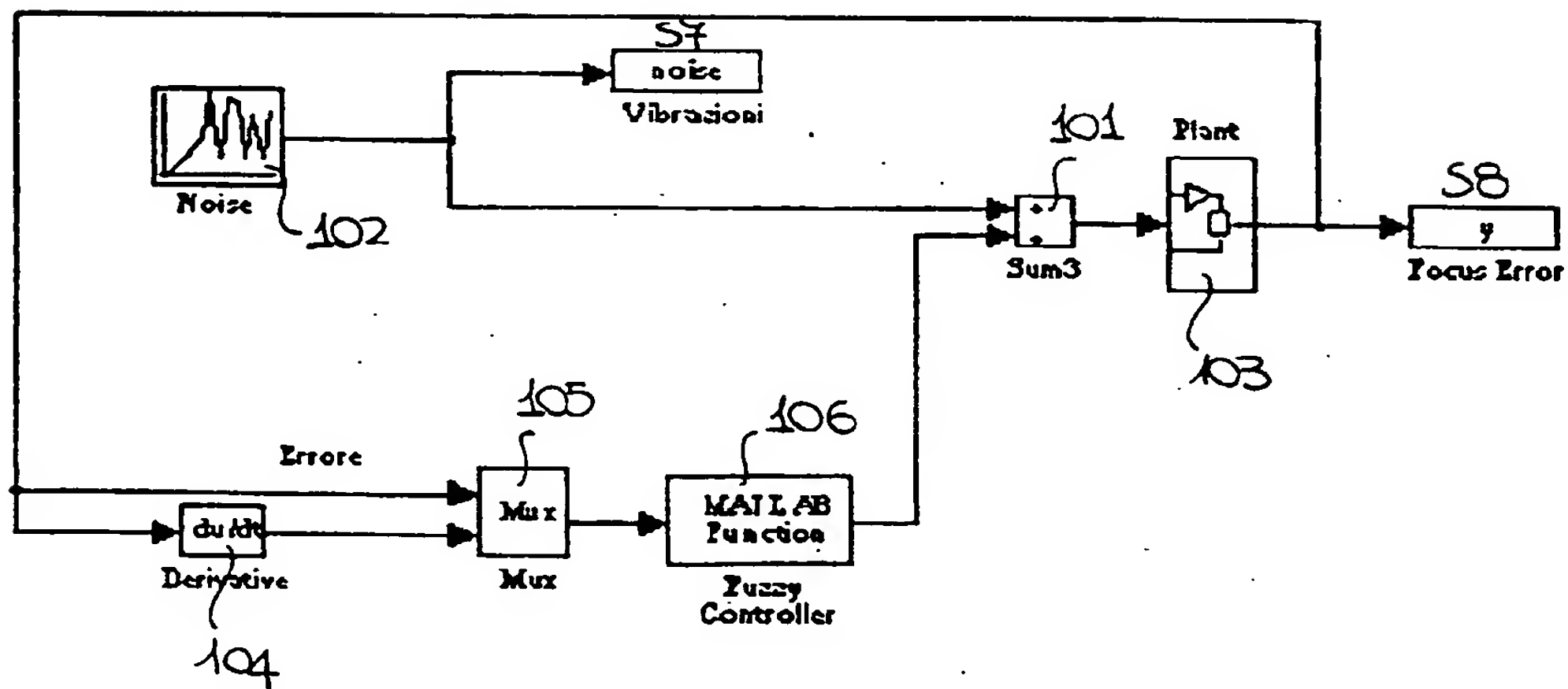


FIG. 10A

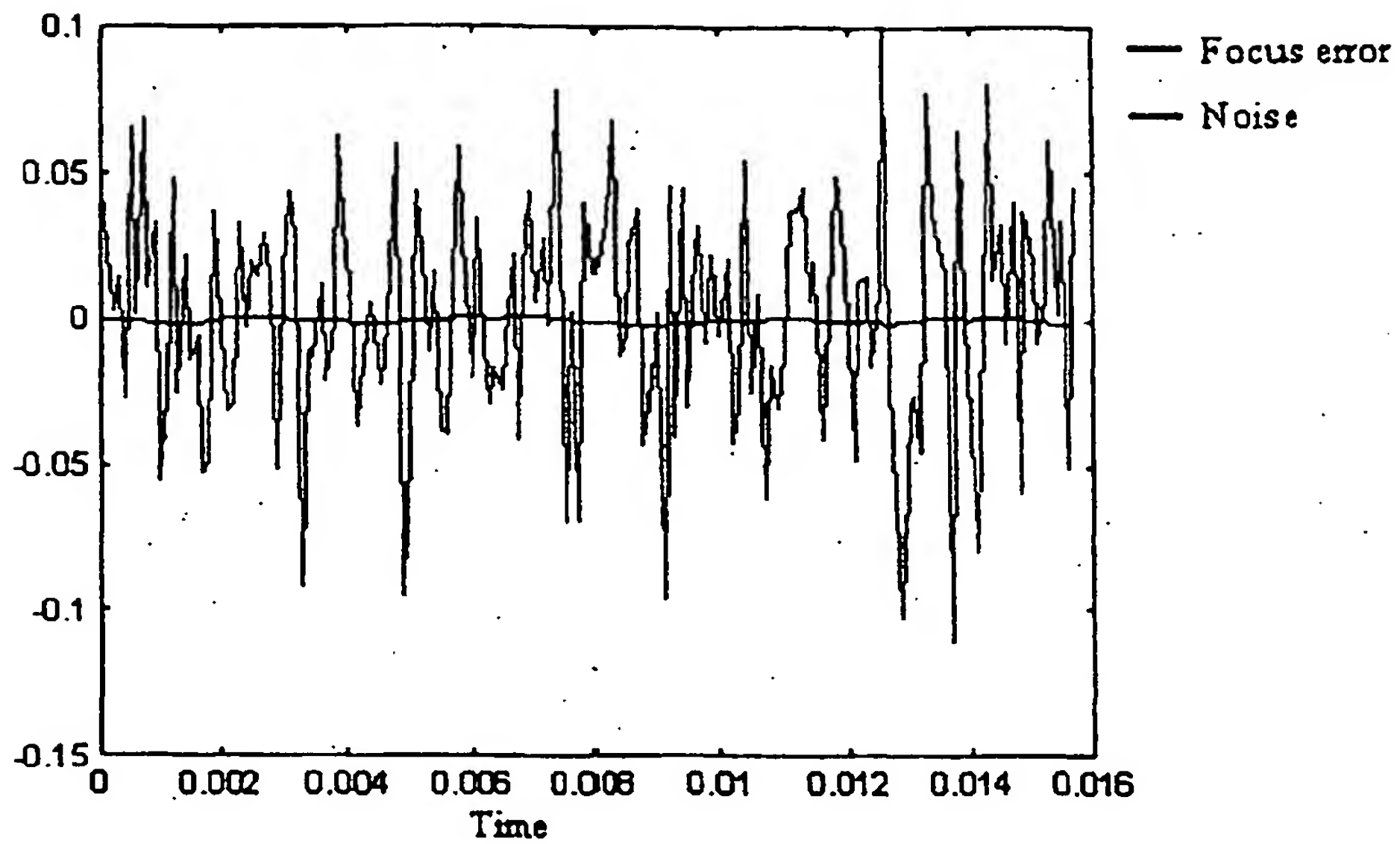


FIG. 10B

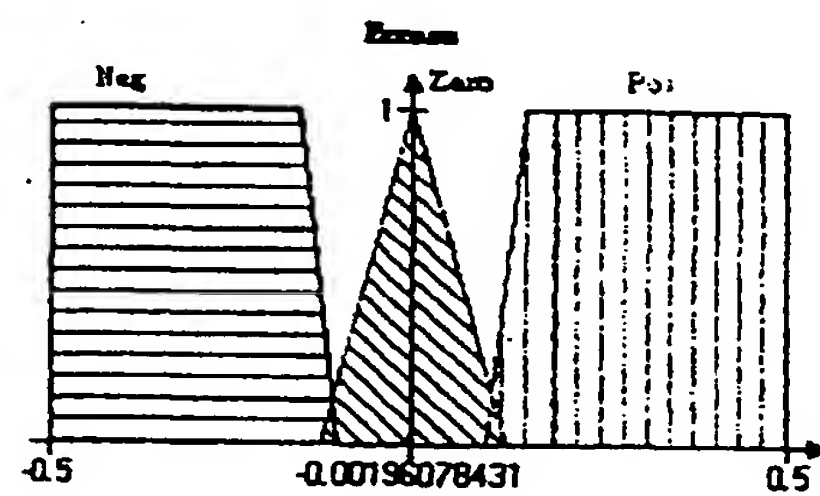


FIG. 12A

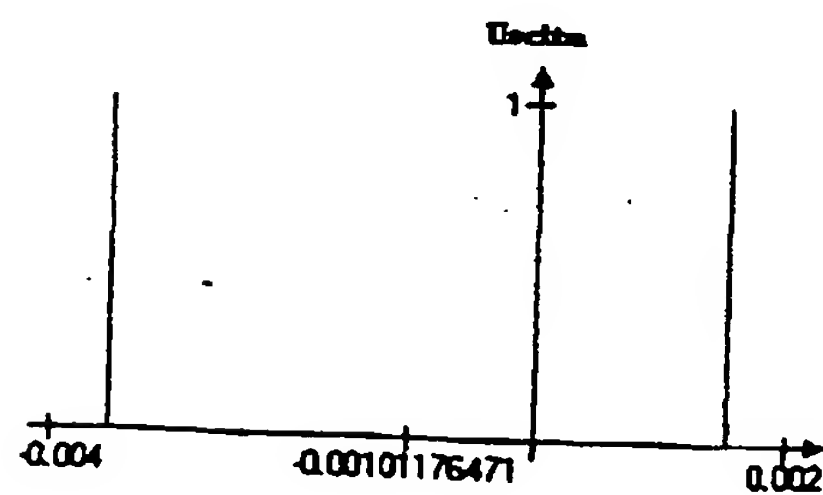


FIG. 12B

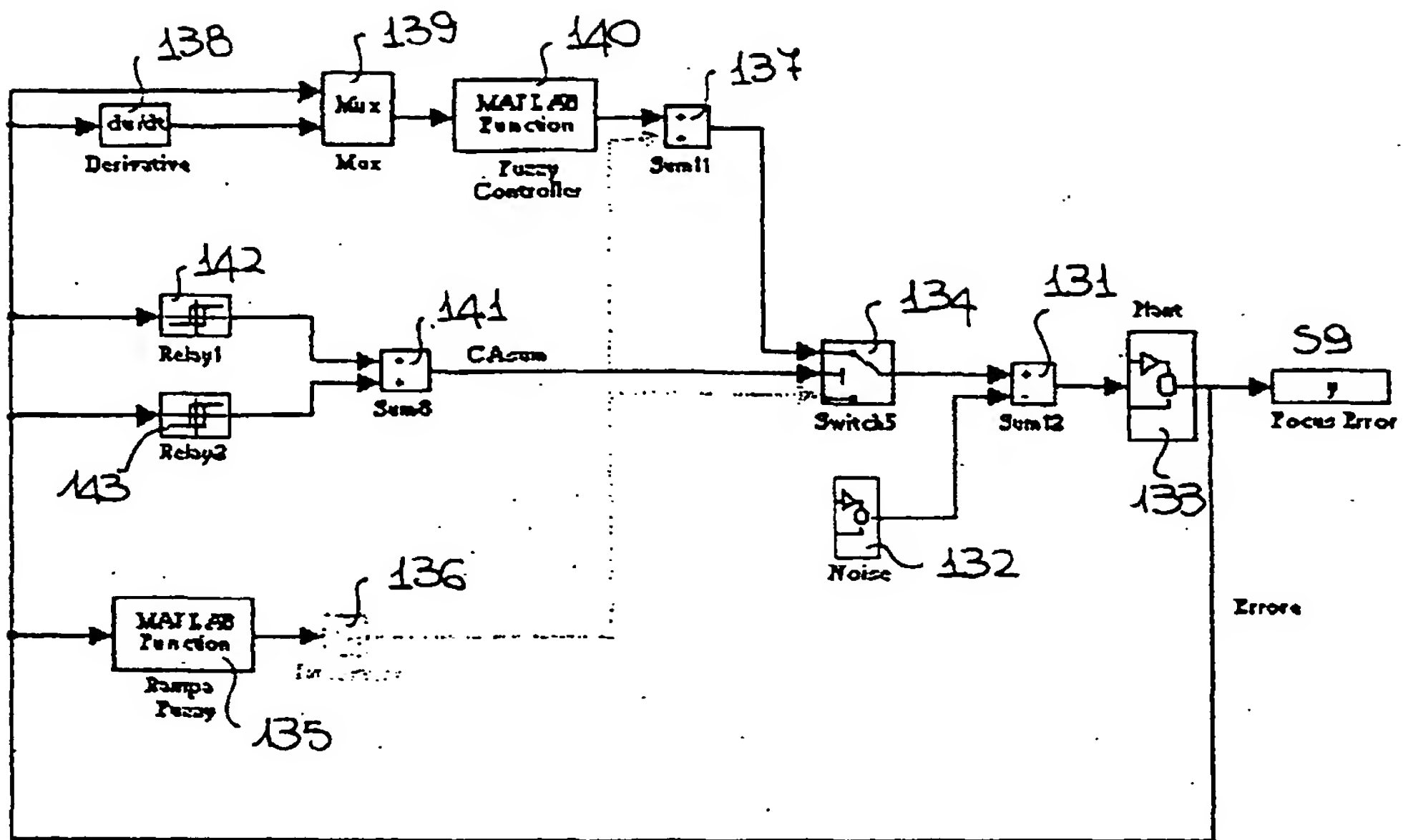


FIG. 13

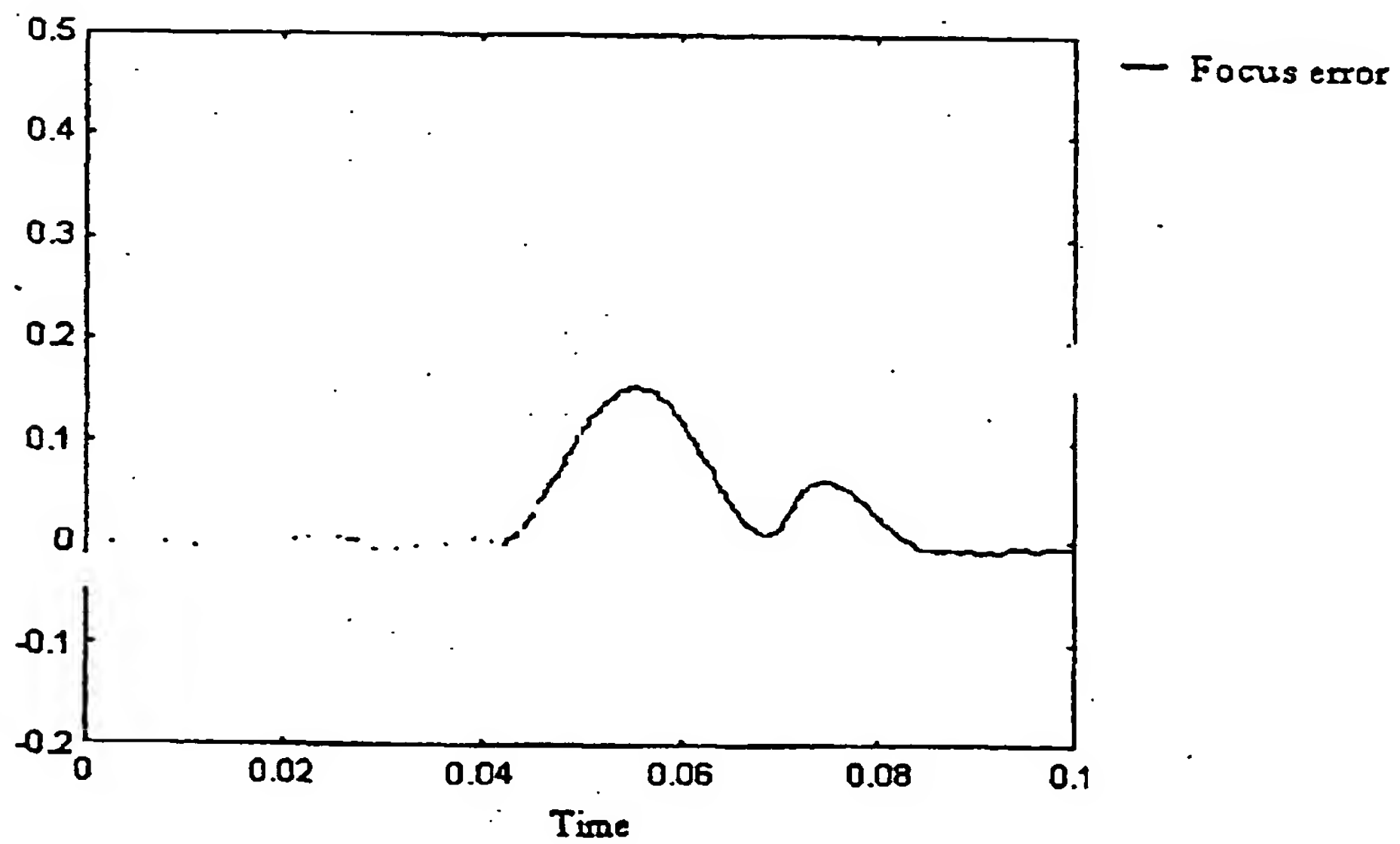


FIG. 14



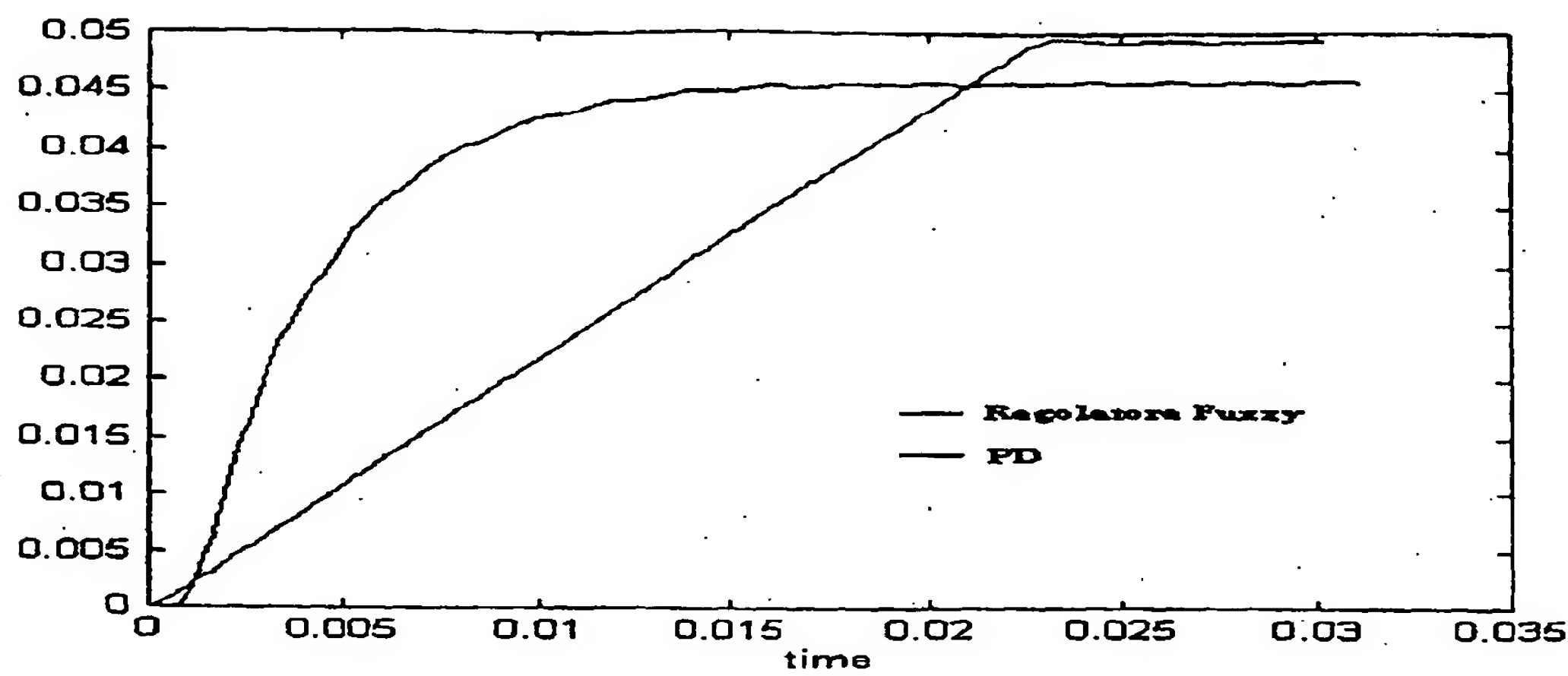


FIG. 15

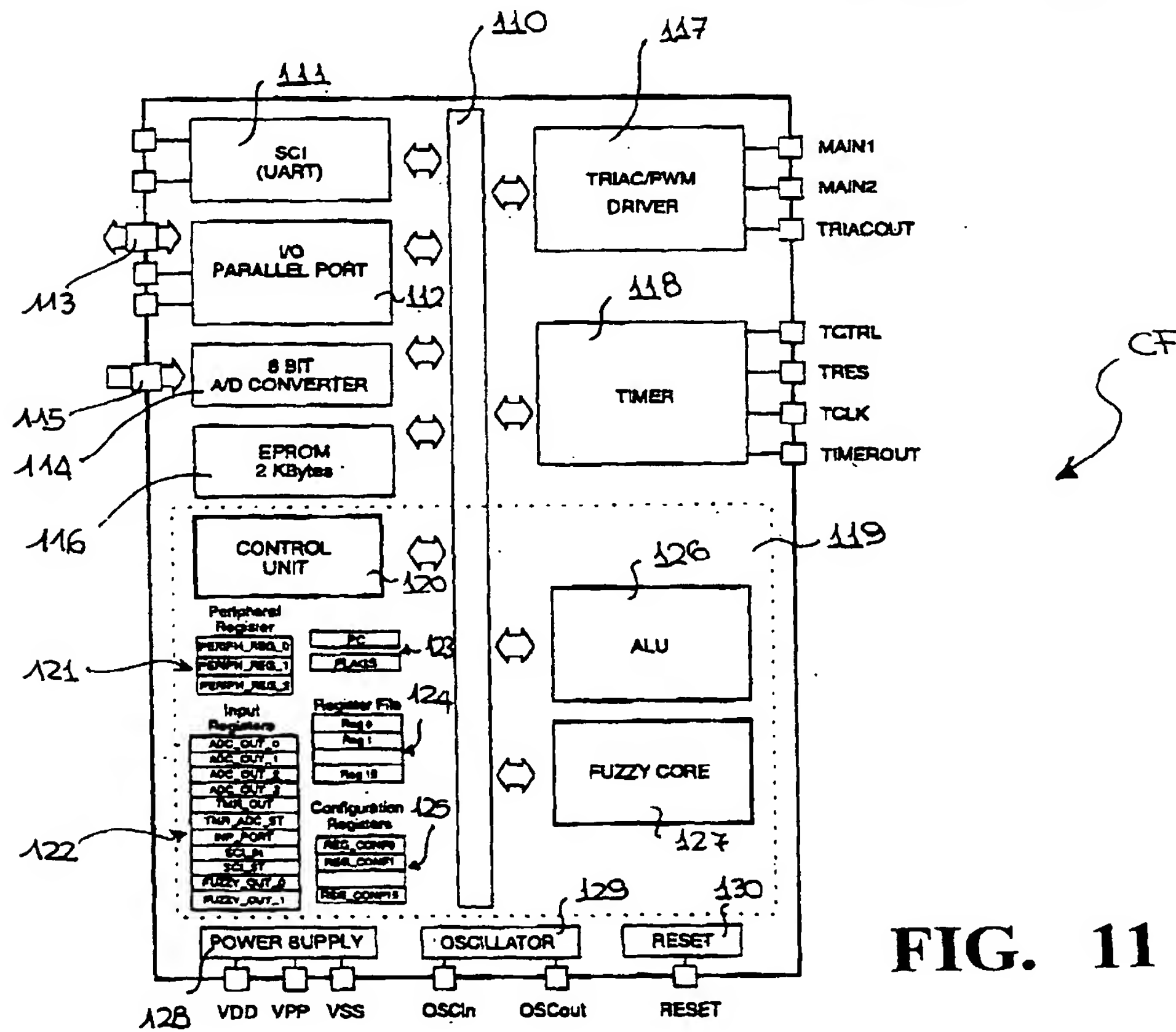


FIG. 11

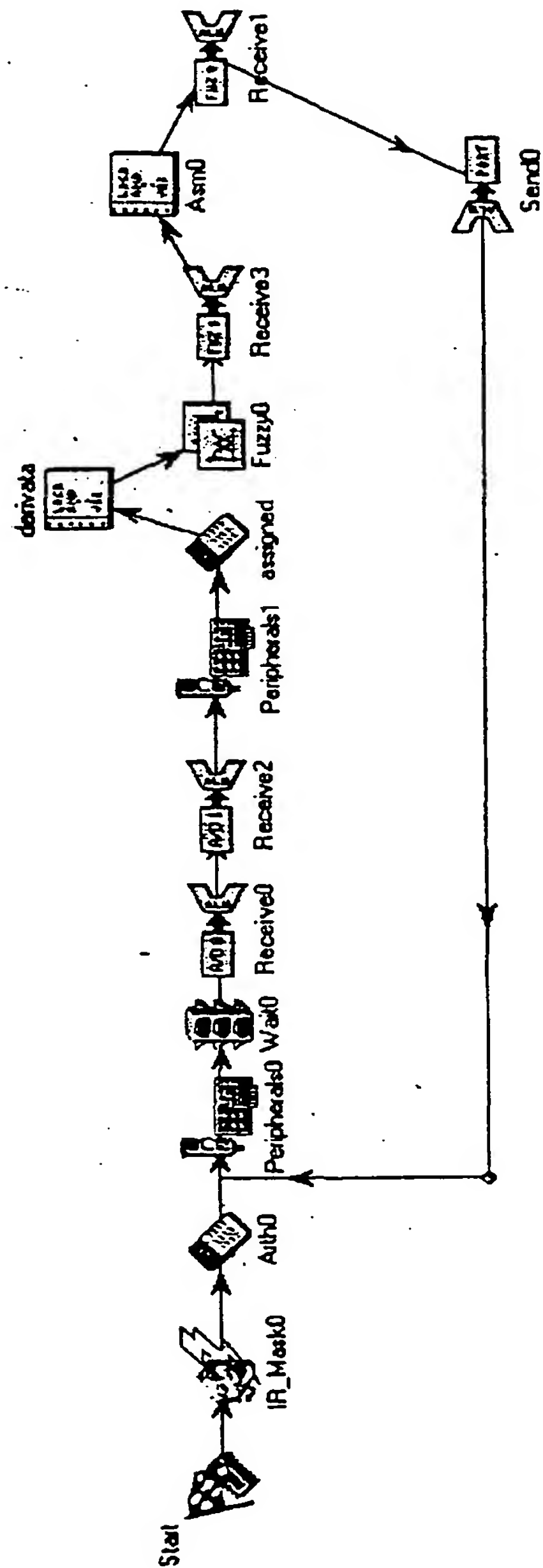


FIG. 16

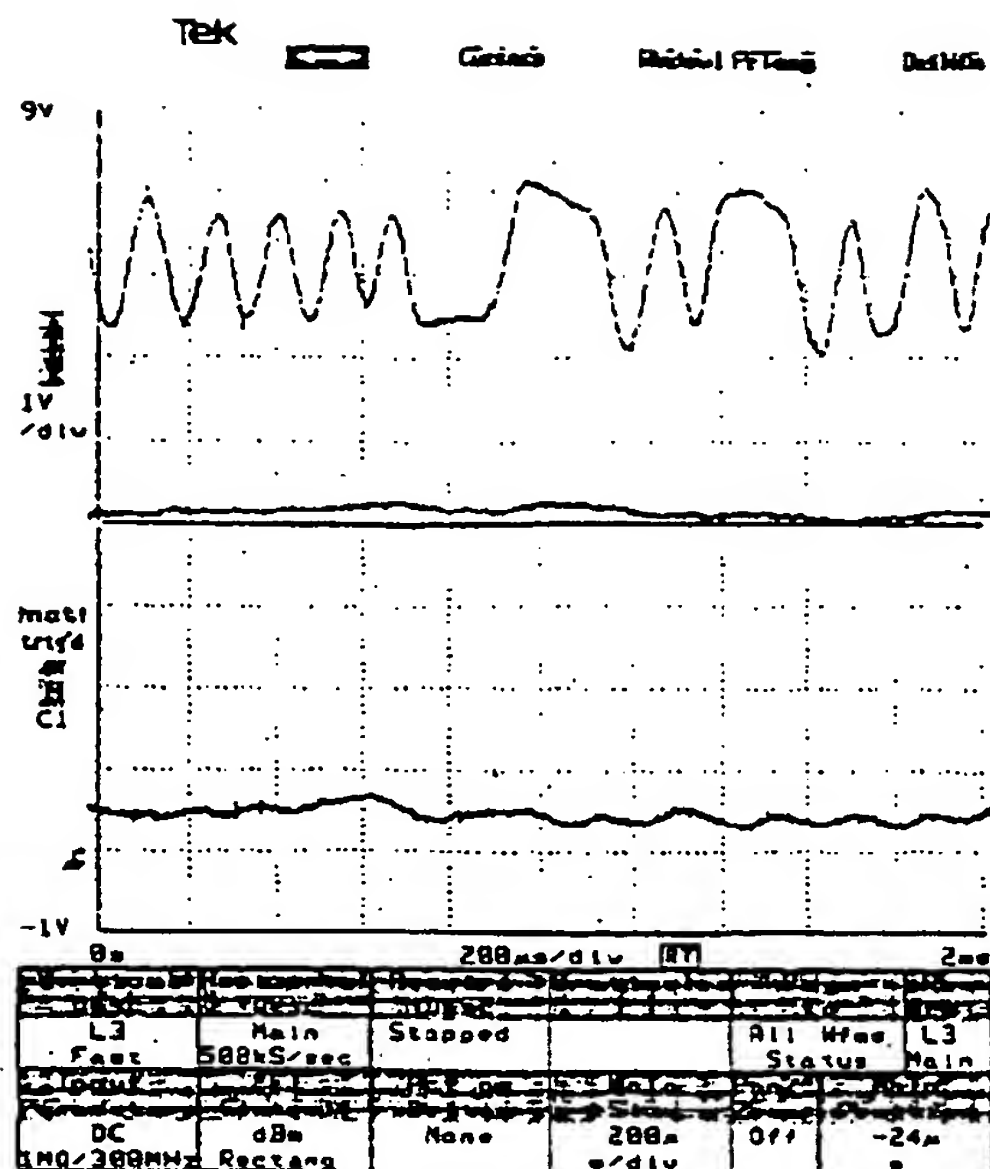


FIG. 17A

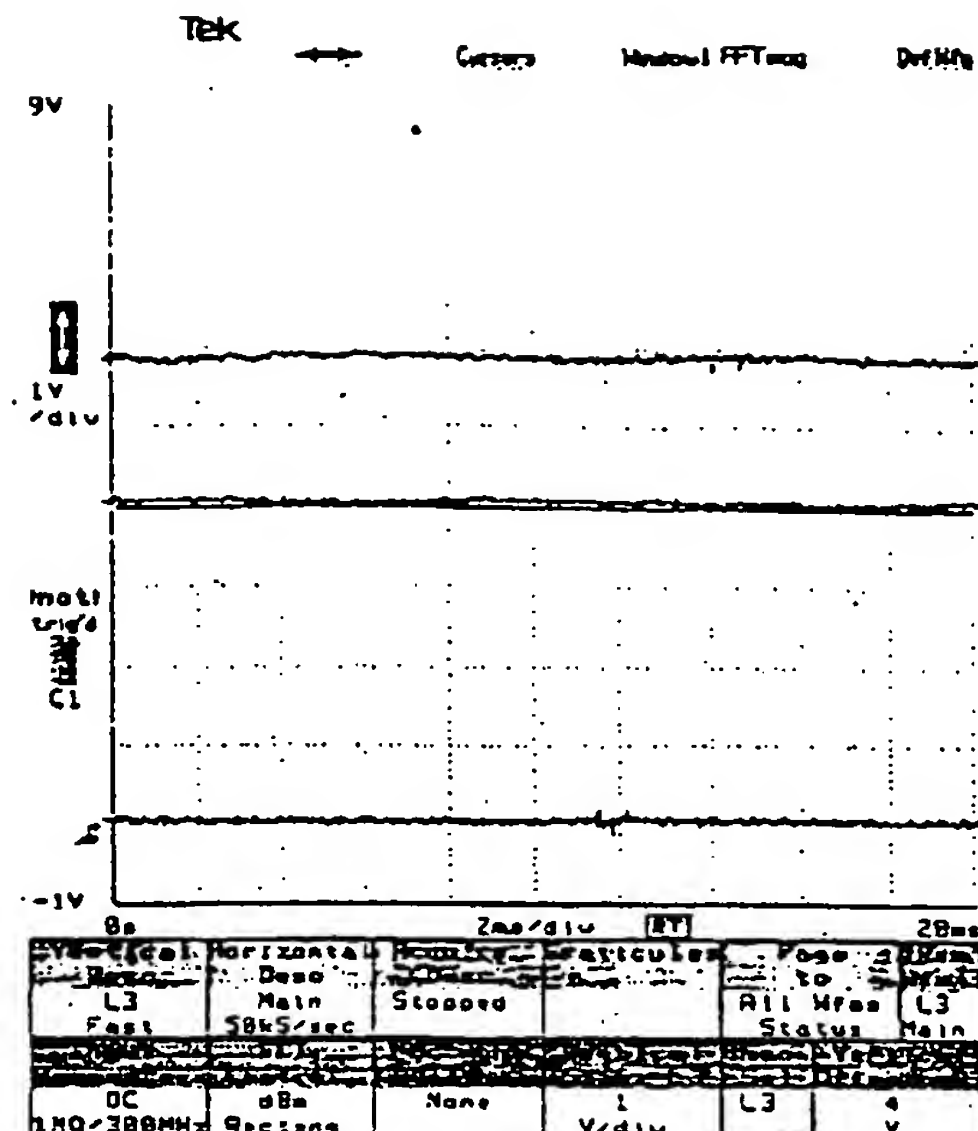


FIG. 17B

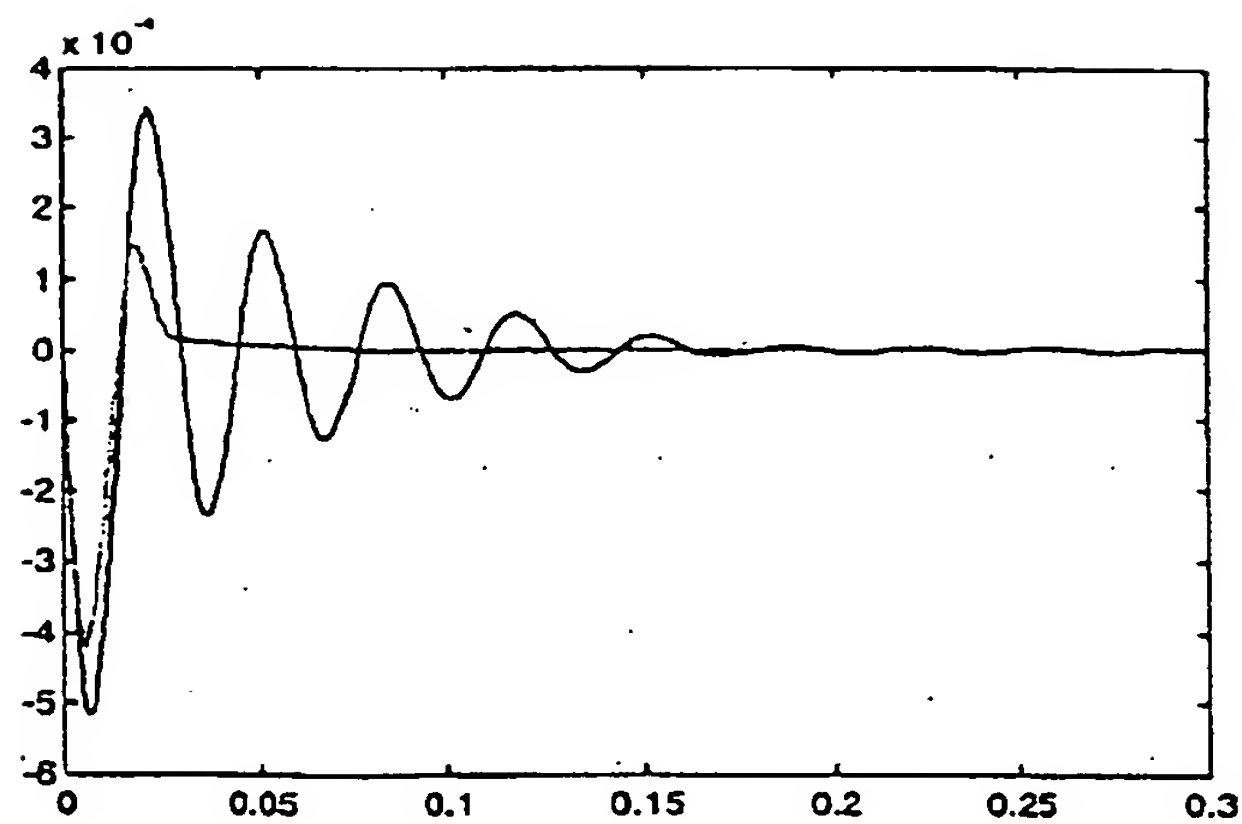


FIG. 18



European Patent  
Office

# EUROPEAN SEARCH REPORT

Application Number  
EP 98 83 0796

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X	PATENT ABSTRACTS OF JAPAN vol. 015, no. 136 (P-1187), 4 April 1991 -& JP 03 015809 A (OMRON TATEISI ELECTRON CO), 24 January 1991 * abstract *	1,10	G11B7/09
Y		2	
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Y	EP 0 676 750 A (LG ELECTRONICS INC) 11 October 1995 * column 13, line 7 - column 14, line 34; figure 8 *	2	
X	US 5 677 995 A (MAGER KLAUS) 14 October 1997 * column 3, line 63 - column 4, line 49; figure 4 *	1,10	
A		5,6	
The present search report has been drawn up for all claims			<b>TECHNICAL FIELDS SEARCHED (Int.Cl.6)</b>  G11B G05B
Place of search <b>THE HAGUE</b>		Date of completion of the search <b>7 May 1999</b>	Examiner <b>Annibal, P</b>
<b>CATEGORY OF CITED DOCUMENTS</b> X : particularly relevant if taken alone Y : particularly relevant if combined with another document of the same category A : technological background O : non-written disclosure P : intermediate document T : theory or principle underlying the invention E : earlier patent document, but published on, or after the filing date D : document cited in the application L : document cited for other reasons & : member of the same patent family, corresponding document			

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The members are as contained in the European Patent Office EDP file on  
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For more details about this annex : see Official Journal of the European Patent Office, No. 12/82

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